

src/apriltag\_node.cpp

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graph TD; A[src/apriltag_node.cpp] --> B[rclcpp/rclcpp.hpp]; A --> C[sensor_msgs/msg/image.hpp]; A --> D[std_msgs/msg/int32_multi_array.hpp]; A --> E[cv_bridge/cv_bridge.h]; A --> F[opencv2/opencv.hpp];
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rclcpp/rclcpp.hpp

sensor\_msgs/msg/image.hpp

std\_msgs/msg/int32  
\_multi\_array.hpp

cv\_bridge/cv\_bridge.h

opencv2/opencv.hpp